

## WEST Search History

DATE: Monday, October 10, 2005

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<input type="checkbox"/>	L6		measuring and displacement and L4	96
<input type="checkbox"/>	L5		measuring displacement and L4	5
<input type="checkbox"/>	L4		mobile robot and L3	884
<input type="checkbox"/>	L3		(robot\$6 or articulat\$3 or automat\$6 or autonomous\$2 or CNC or machine\$2 or mechanical device or mechan\$6 or servomechan\$4) and (camera or video or image sensor)	447119
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<input type="checkbox"/>	L1		10/697282	1

END OF SEARCH HISTORY

**Key:** IEEE JNL = IEEE Journal or Magazine, IEE JNL = IEE Journal or Magazine, IEEE CNF = IEEE Conference, IEE CNF = IEE Conference, IEEE STD = IEEE Standard

- 1. A kinematic-independent dead-reckoning sensor for indoor mobile robotics**  
Bonarini, A.; Matteucci, M.; Restelli, M.;  
Intelligent Robots and Systems, 2004. (IROS 2004). Proceedings. 2004  
IEEE/RSJ International Conference on  
Volume 4, 28 Sept.-2 Oct. 2004 Page(s):3750 - 3755 vol.4  
**IEEE CNF**
  
- 2. Computation of shape through controlled active exploration**  
Smith, C.E.; Papanikolopoulos, N.P.;  
Robotics and Automation, 1994. Proceedings., 1994 IEEE International  
Conference on  
8-13 May 1994 Page(s):2516 - 2521 vol.3  
**IEEE CNF**


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[Vision-Based Sensor for Real-Time Measuring of Surface Traction Fields](#)

Figure 4 shows an **image** captured by the CCD **camera** and sent directly to a PC. ... Similarly, to operate dexterously, **robots** must sense both the grasping and ...

[doi.ieeecomputersociety.org/10.1109/MCG.2005.27](http://doi.ieeecomputersociety.org/10.1109/MCG.2005.27) - [Similar pages](#)

[Displacement Sensors](#)

MICRO-EPSILON is an authority in providing **displacement** solutions.  
[micro-epsilon.com](http://micro-epsilon.com)

[Briefs: Photonics](#)

Interferometer for **Measuring Displacement** to Within 20 pm NPO21221 ...

MFS31718; Custom Software for Infrared **Camera Image** Acquisition and Control INDIGO0403 ...

[www.nasatech.com/Briefs/photonics.html](http://www.nasatech.com/Briefs/photonics.html) - 68k - [Cached](#) - [Similar pages](#)

[Optical Measurement Systems for Industrial Inspection III](#) ...

... grid is the grid on the **robot** marks ... structured light system and the CCD **camera** takes **images** ... the most powerful methods for **measuring displacement** deformation or ...

[www.spie.org/Conferences/Programs/03/eom/conferences/index.cfm?fuseaction=5144](http://www.spie.org/Conferences/Programs/03/eom/conferences/index.cfm?fuseaction=5144) - 101k - Supplemental Result - [Cached](#) - [Similar pages](#)

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... DMD Reflection-Type CCD **Camera** Motoharu Fujigaki ... 211 Design Of Micro **Robots** With Microgrippers ... Laser Interferometry Method For **Measuring Displacement** Field Of ...

[www.icem04.org/Detailed%20Technical%20Programme%20\(12Oct04\).pdf](http://www.icem04.org/Detailed%20Technical%20Programme%20(12Oct04).pdf) - Supplemental Result - [Cached](#) - [Similar pages](#)

[Residual Waste Volume Measurement for Hanford Underground Storage](#) ...

A point in the **image** of one **camera** must be identified and located. The

same point must be located in the **image** of the second **camera**. ...

[www.tanks.org/ttgdoc/whcsdwmta180.htm](http://www.tanks.org/ttgdoc/whcsdwmta180.htm) - 47k - [Cached](#) - [Similar pages](#)

[Research centers, Faculty of Mechanical Eng., Technion](#)

**Motion** and interaction of inertial particles in the turbulent atmosphere ...

New **robot** structures, parallel **robots**, miniature **robots**, medical **robots**, ...

[meeng.technion.ac.il/Research/Centers/centers.html](http://meeng.technion.ac.il/Research/Centers/centers.html) - 38k -

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[\[PS\] Hough Localization for Mobile \*\*Robots\*\* in Polygonal Environments](#) ...

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sponds to errors in the calibration of the **camera**. ffl **robot** bumps: random movements of ... These samples are generated during **robot motion** using odometry ...

[www.dis.uniroma1.it/~iocchi/publications/iocchi-RAS02.ps.gz](http://www.dis.uniroma1.it/~iocchi/publications/iocchi-RAS02.ps.gz) - [Similar pages](#)

**[PDF] Simulating self motion II: A virtual reality tricycle**

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ongoing pose of a mobile **robot** cannot be estimated using internal sensors only, and ... is the current state vector ( $u, v$  **image** coordinates) and  $v$  ...  
[www.cs.yorku.ca/~jenkin/papers/2002/vr2.pdf](http://www.cs.yorku.ca/~jenkin/papers/2002/vr2.pdf) - [Similar pages](#)

**[PDF] Salient Design Considerations**

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**motion** attached to the bottom hull and two for horizontal **motion** located on the ... An integral part of the vision system is the RHP-320WP infrared **camera** ...

[www.auvsi.org/competitions/2000/Papers/StevensPaper.pdf](http://www.auvsi.org/competitions/2000/Papers/StevensPaper.pdf) - [Similar pages](#)

**[PDF] Vision-Based Sensor for Real- Time Measuring of Surface Traction ...**

File Format: PDF/Adobe Acrobat

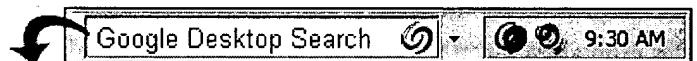
ment of B to a new configuration describes the **motion**., which we define as.  
 $u(x, t) = \kappa(x, t) - x$  ... **camera image**. Given applied traction field  $\Phi$ , we used ...

[ieeexplore.ieee.org/iel5/38/30111/01381228.pdf?arnumber=1381228](http://ieeexplore.ieee.org/iel5/38/30111/01381228.pdf?arnumber=1381228) -

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